Amendments to the Claims:

Please AMEND the pending claims as stated below:

1. (**Currently Amended**) A method comprising the step of:

a) generating a hedge signal **with an adaptive control system** to avoid adaptation to at least one characteristic of [[an]] **the** adaptive control system**, the characteristic having an effect to which adaptation would be detrimental to control of a plant with the adaptive control system**[[and/or a plant controlled by the adaptive control system]].

2. (**Original**) A method as claimed in claim 1 further comprising the steps of:

b) modifying a commanded state signal with the hedge signal; and

c) generating a reference model state signal based on the commanded state signal modified with the hedge signal in the step (b).

3. (**Previously Presented**) A method as claimed in claim 2 further comprising the step of:

d) generating a tracking error signal based on the reference model state signal and a plant state signal; and

e) generating an adaptive control signal based on the tracking error signal to adapt control response of the adaptive control system.

4. (**Cancel**)

5. (**Cancel**)

6. (**Cancel**)

7. (**Cancel**)

8. (**Cancel**)

9. (**Cancel**)

10. (**Original**) A method as claimed in claim 1 wherein the plant is an aircraft and/or spacecraft.

11. (**Original**) A method as claimed in claim 1 wherein the plant is an automobile.

12. (**Currently Amended**) A method as claimed in claim 1 wherein the [[plan]] **plant** is an unmanned vehicle.

13. (**Currently Amended**) In an adaptive control system for controlling a plant, a hedge unit coupled to receive at least one control signal and a plant state signal, the hedge unit generating a hedge signal based on the control signal, the plant state signal, and a hedge model including a first model having a characteristic **of the adaptive control system** to which the adaptive control system is not to adapt, and a second model not having the characteristic to which the adaptive control system is not to adapt, the hedge signal used in the adaptive control system to remove an effect of the characteristic from a signal supplied to an adaptation law unit of the adaptive control system so that the adaptive control system does not adapt to the characteristic in controlling the plant**, the characteristic having an effect to which adaptation would be detrimental to control of a plant with the adaptive control system**.

14. (**Cancel**)

15. (**Cancel**)

16. (**Original**) An adaptive control system as claimed in claim 13 wherein the characteristic pertains to a control limit of the actuator used to control the plant.

17. (**Original**) An adaptive control system as claimed in claim 13 wherein the control limit pertains to actuator end points.

18. (**Original**) An adaptive control system as claimed in claim 13 wherein the control limit pertains to actuator dynamics.

19. (**Original**) An adaptive control system as claimed in claim 13 wherein the control limit pertains to a rate limit of the actuator.

20. (**Original**) An adaptive control system as claimed in claim 13 wherein the control limit pertains to quantization effects associated with the actuator.

21. (**Original**) An adaptive control system as claimed in claim 13 wherein the plant is an aircraft and/or spacecraft.

22. (**Original**) An adaptive control system as claimed in claim 13 wherein the plant is an automobile.

23. (**Original**) An adaptive control system as claimed in claim 13 wherein the plant is an unmanned vehicle positioned remotely from an operator.

Please add NEW Claims 24-32 as follows:

24. (**New**) A method as claimed in claim 1 wherein the characteristic pertains to a control limit of the actuator used to control the plant.

25. (**New**) A method as claimed in claim 26 wherein the control limit pertains to actuator end points.

26. (**New**) A method as claimed in claim 26 wherein the control limit pertains to actuator dynamics.

27. (**New**) A method as claimed in claim 26 wherein the control limit pertains to a rate limit of the actuator.

28. (**New**) A method as claimed in claim 26 wherein the control limit pertains to quantization effects associated with the actuator.

29. (**New**) A method as claimed in claim 1 wherein the characteristic relates to a control limit of the sensor.

30. (**New**) A method as claimed in claim 1 wherein the control limit relates to a speed at which the sensor can sense a state of the plant.

31. (**New**) A system as claimed in claim 13 wherein the characteristic relates to a control limit of the sensor.

32. (**New**) A system as claimed in claim 31 wherein the control limit relates to a speed at which the sensor can sense a state of the plant.